ABSTRACT

A method for machining workpieces by means of a multiaxial manipulator, such as an industrial robot, with a tool moved proportionally by a control unit of the manipulator and which can perform characteristic movements with several degrees of freedom is characterized in that the degrees of freedom of the tool are evaluated together with the degrees of freedom of axes of the manipulator in real time for moving a tool tip (TCP) in accordance with a predetermined, continuous machining path or a portionwise continuous machining geometry (step function) and for determining a movement of the manipulator. The invention also proposes a device suitable for performing the aforementioned method, in which the tool and a tool tip, during workpiece machining, are movement-controllable by the manipulator control unit. In this way it is possible to drastically reduce the overall machining time.